

FIG. 1

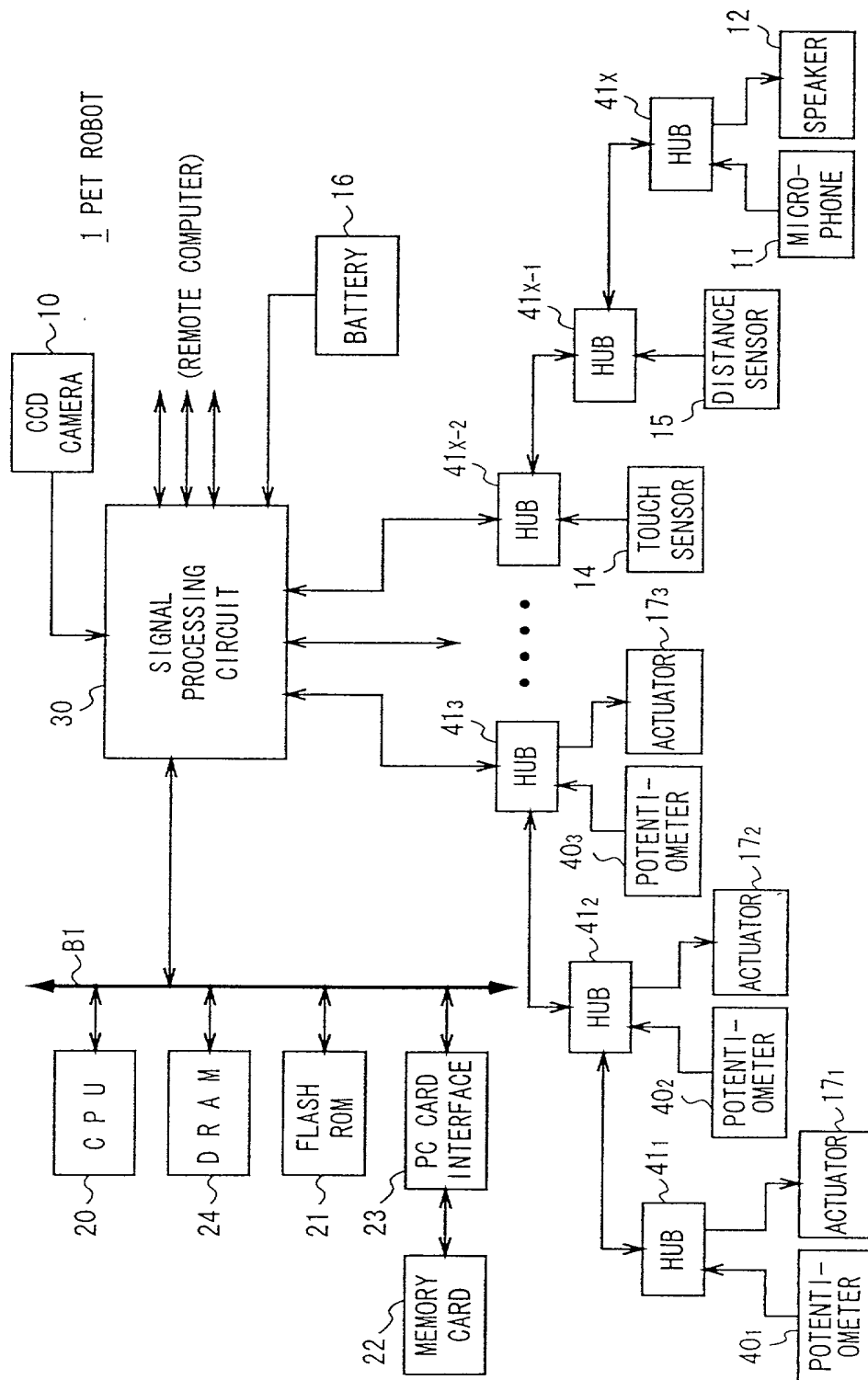


FIG. 2

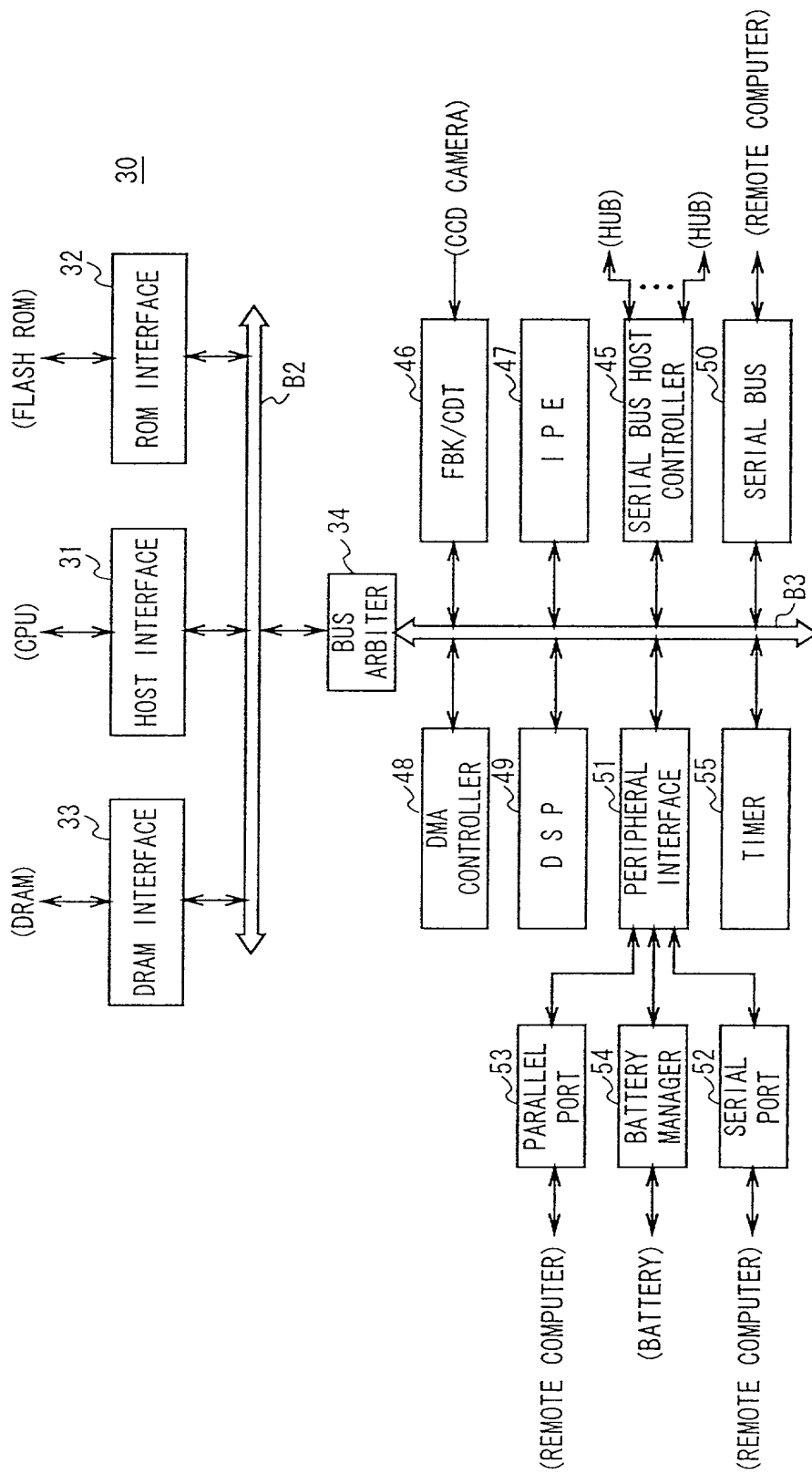


FIG. 3

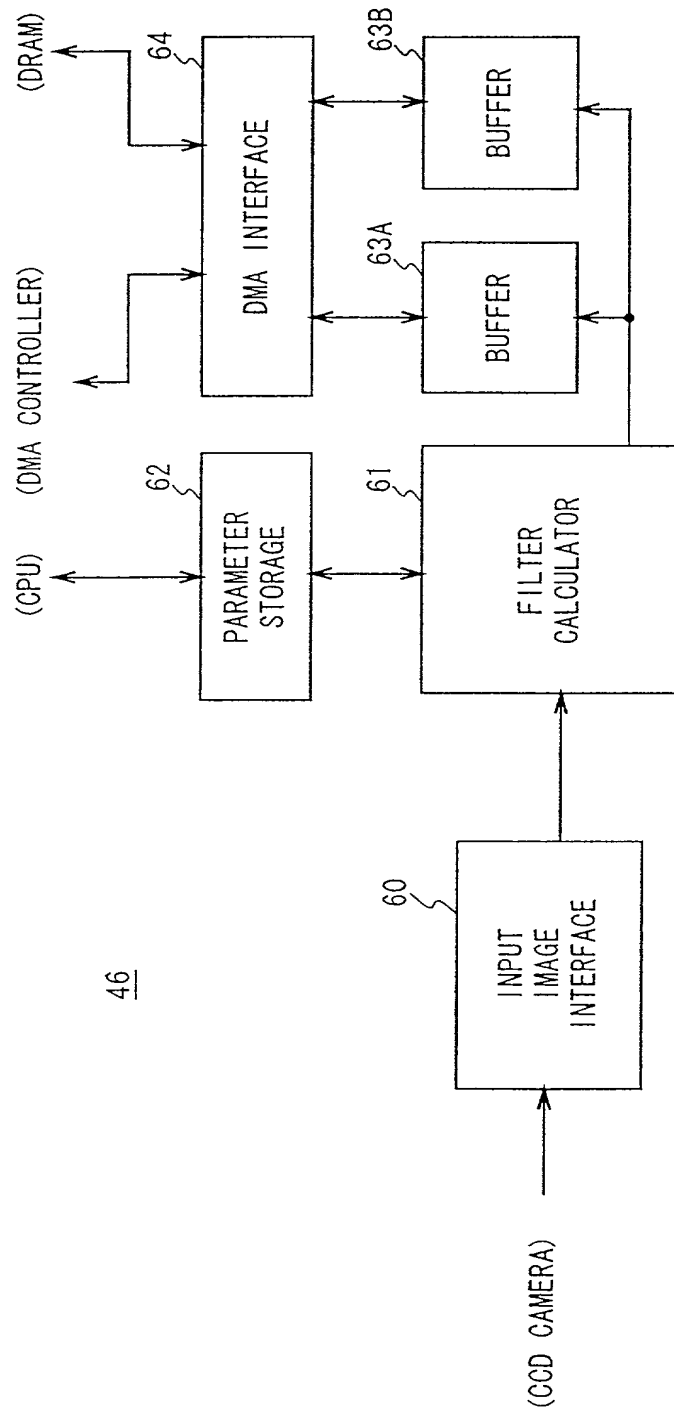


FIG. 4

Bit	31302928272625242322212019181716151413121110 9 8 7 6 5 4 3 2 1 0																															
R/W	Current Source Start Address																															~85
R/W	Current Destination Start Address																															~86
R/W	Done Count											B u s y											Current Status	~87								
89																																~88
R	Default Source Start Address																															~73
R	Default Destination Start Address																															~74
R											I n t e n s i t y	B u s y	I n t e n s i t y	B u s y											Default Transfer Size	~75						
80																																~76
79																																~77
																																~78
R	Source Address Skip																															~81
R	Destination Address Skip																															~82
R	Source/Destination End Address																															~83
R	Next DMAList Pointer																															~84

FIG. 5

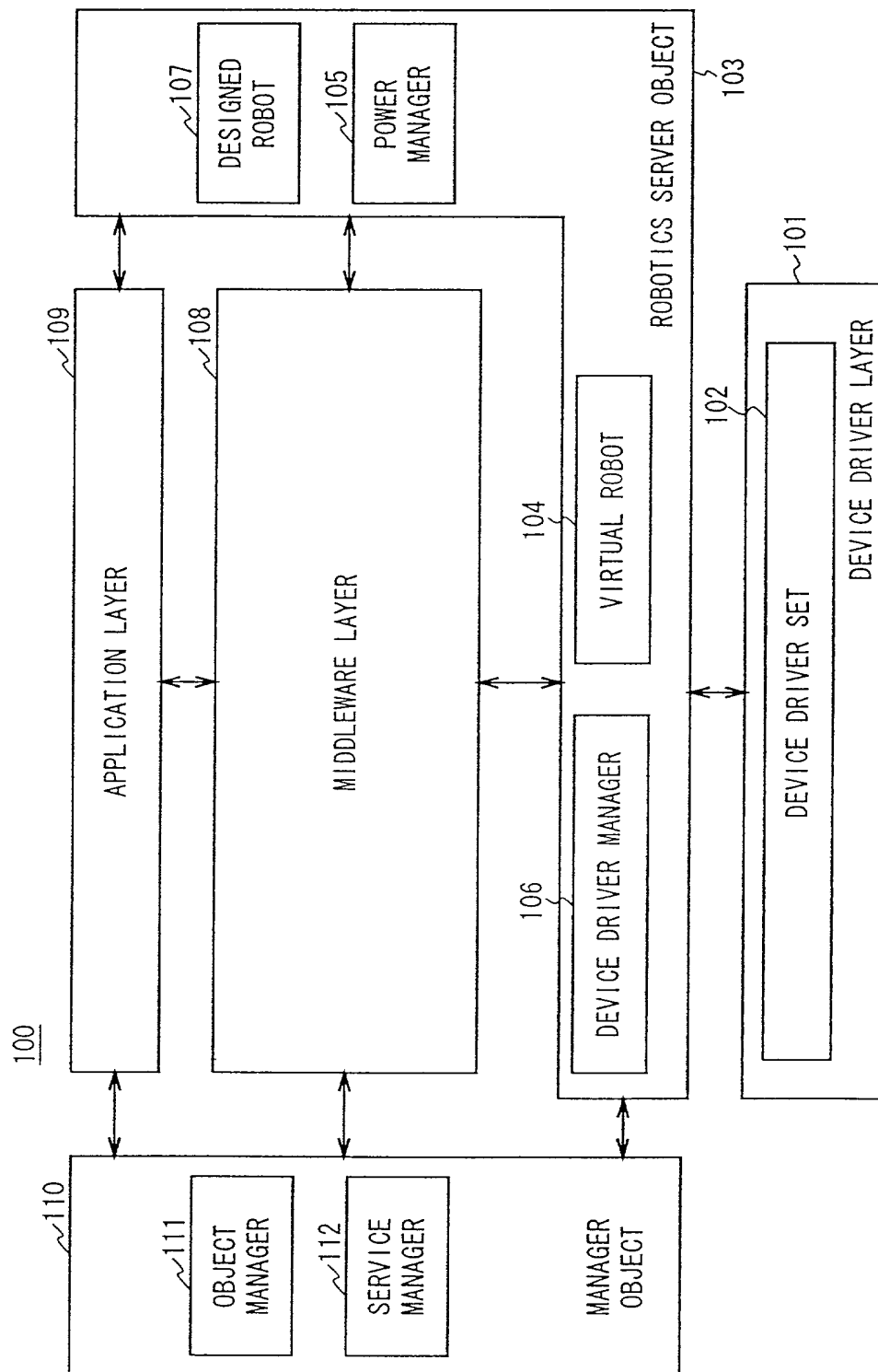


FIG. 6

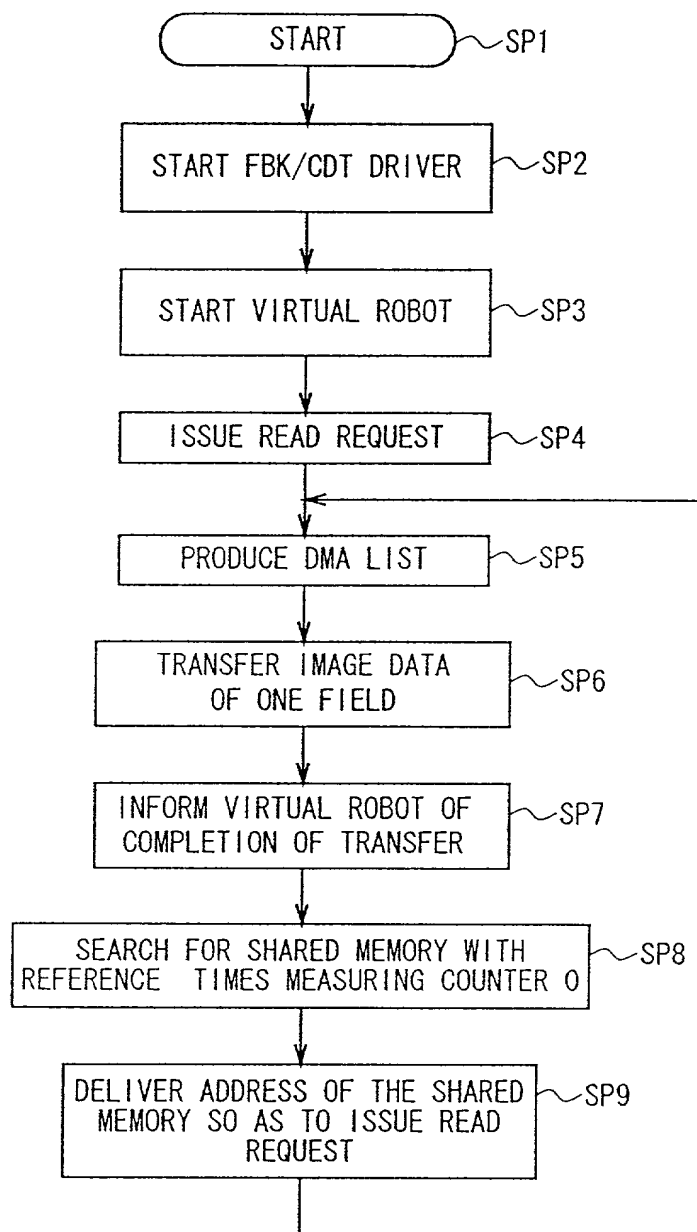


FIG. 7

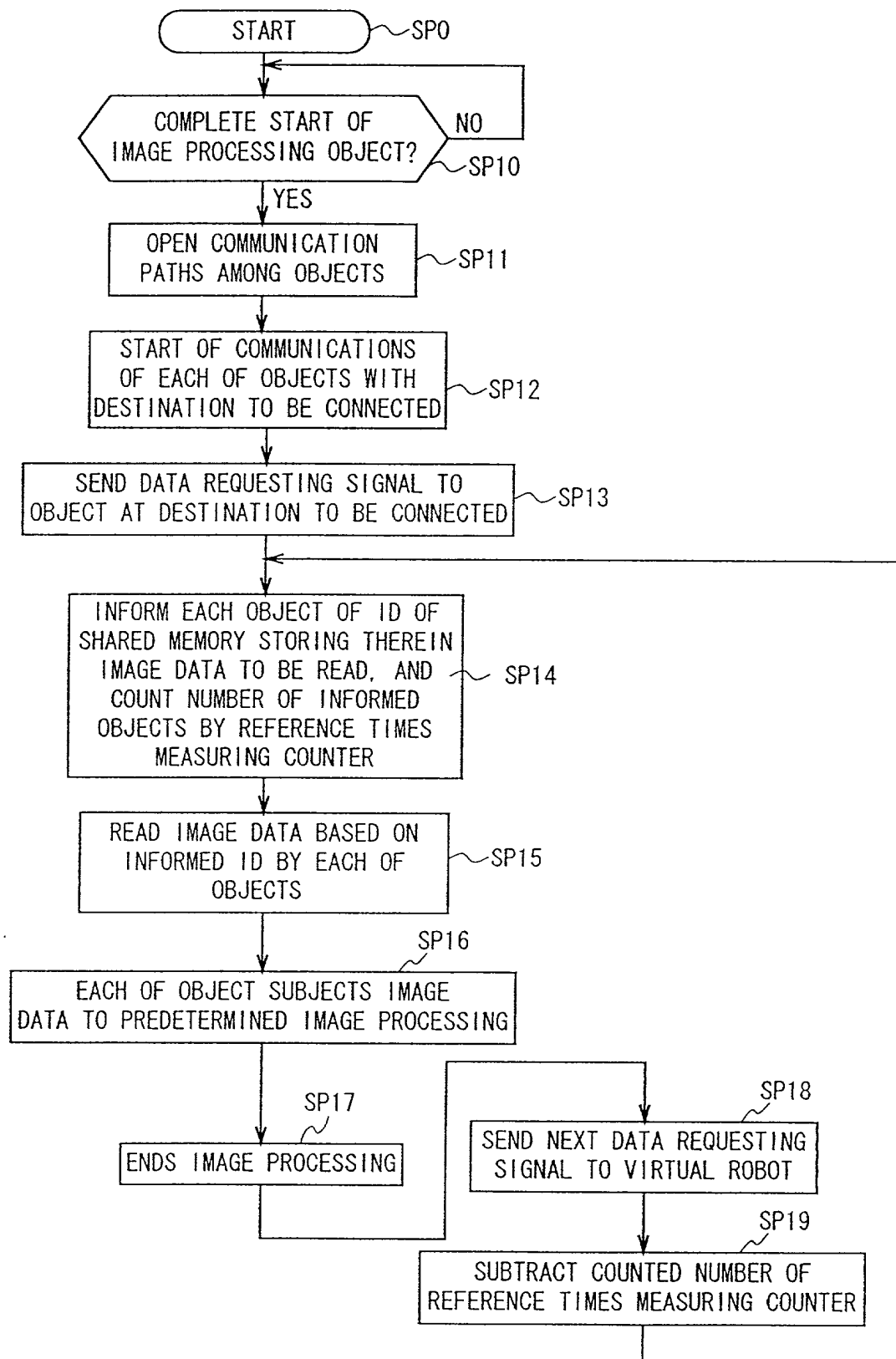


FIG. 8



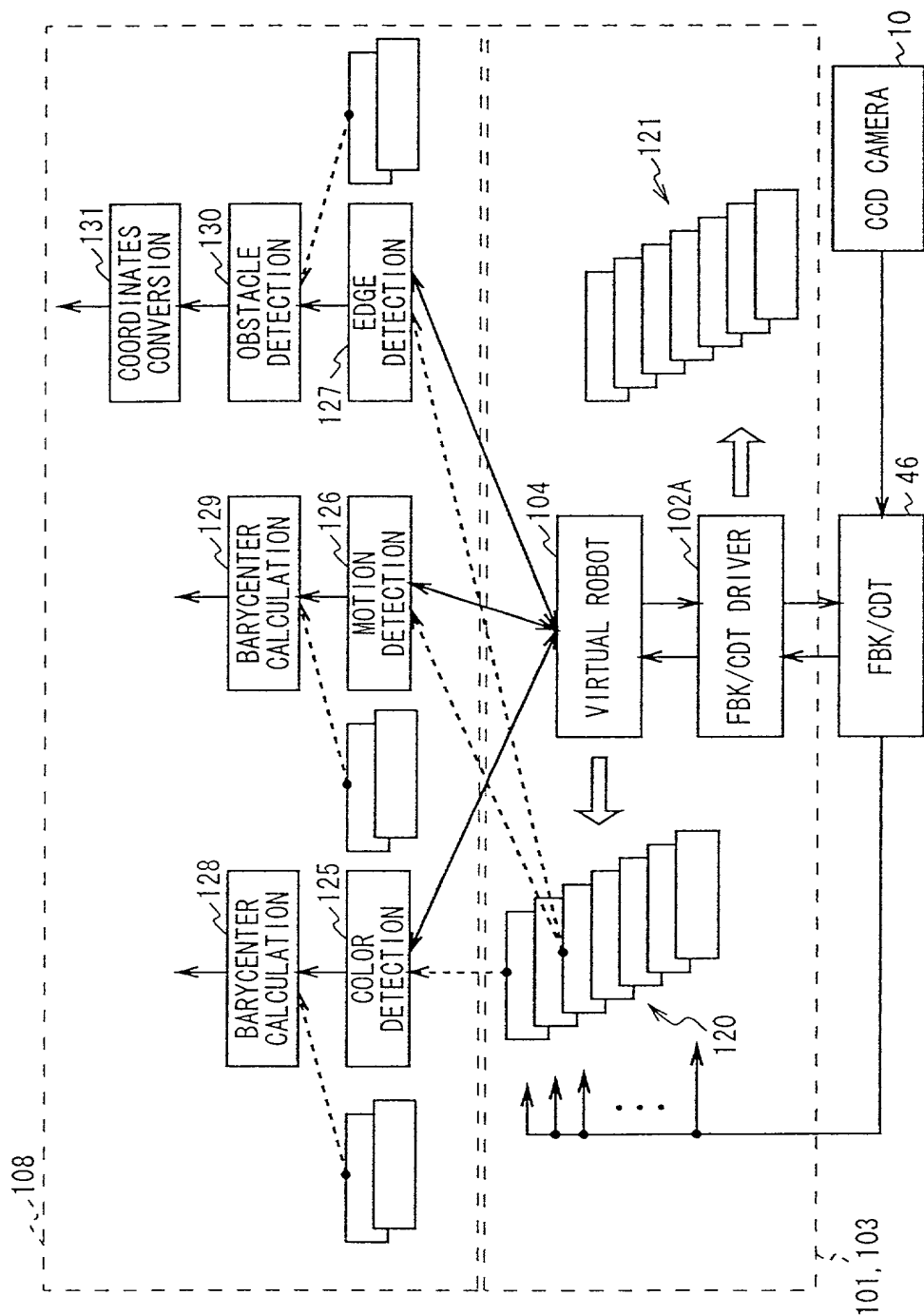


FIG. 9

## Explanation of Reference Numerals

1...pet robot, 2...head portion, 3...main body portion, 4...leg portion, 5...tail portion, 10...CCD camera, 11...microphone, 12...speaker, 15...distance sensor, 16...battery, 17...actuator, 20...CPU, 21...flash ROM, 22...memory card, 24...DRAM, 30...signal processing circuit, 34...bus arbiter, 40...potentiometer, 41...hub, 45...serial bus host controller, 46...FBK/CDT, 47...IPE, 48...DMA controller.